

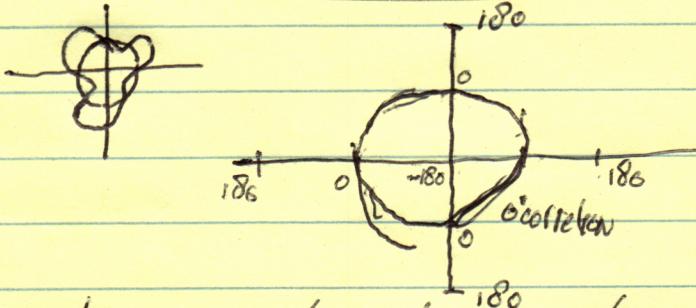
~~270 + 120~~ head 300  
 heading cog + ~~dest~~ cog  
~~120~~ 120  
 want 270 cog  
~~120~~ 120  
 $270 + 120 = 390 = 30$

heading      cog      COMPASS correction angle  $c$  \* different headings  
 heading      cog  
 $cog = heading + c \Rightarrow c = heading - cog$   
 $c = \text{average}(heading - cog)$  over all time  
 → add reset function

~~drift~~ → correct again when bending to autopilot \* uses wrong heading

drift correction: \* speed dependent

\* dependent on current conditions  
\* dependent on course



→ just use 360 \* correction values for now

drift correction

heading      cog      \* we don't know speed through water or  
 what our speeds should be so we can't determine  
 angle and amount of drift? NOT TRUE  
 simply heading - cog

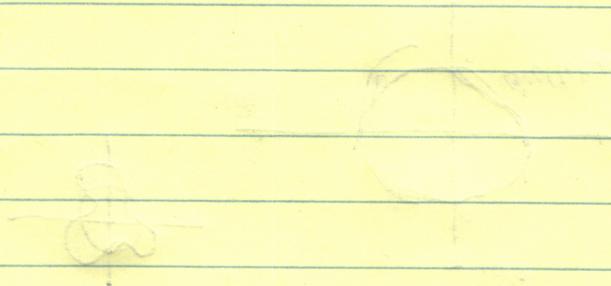
and you can

see the water and the sky and the clouds

in the water you can see the fish

the fish

the fish are swimming in the water



the water is clear

you can see the fish

the fish

the fish are swimming in the water

the fish are swimming in the water